

EUROPEAN PATENT OFFICE

Patent Abstracts of Japan

PUBLICATION NUMBER : 10287262
PUBLICATION DATE : 27-10-98

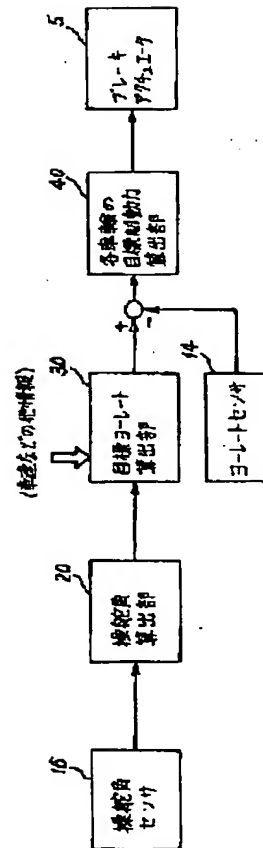
APPLICATION DATE : 16-04-97
APPLICATION NUMBER : 09099020

APPLICANT : NISSAN MOTOR CO LTD;

INVENTOR : FUKUYAMA KENSUKE;

INT.CL. : B62D 6/00 G01B 21/22 // B62D101:00
B62D113:00 B62D137:00

TITLE : BEHAVIOR CONTROL DEVICE FOR
VEHICLE



ABSTRACT : PROBLEM TO BE SOLVED: To enable a device to immediately perform behavior control in accordance with a steering angle even by not detecting a neutral position when an engine is started, in this case, so as to prevent also generation of hunting.

SOLUTION: In a calculating part 20, during the time a neutral position is not detected based on a signal of a sensor 16, and a steering angle can not be detected, a steering angle memory value when an engine is stopped, and a steering amount calculated from an integrated value of number of pulses from the sensor 16 after the engine is started, are added, and a steering angle estimated value is obtained. In a calculating part 30, based on the steering angle estimated value, a target yaw rate is calculated, in a calculating part 40, in accordance with a deviation between a yaw rate detection value of a sensor 14 and the target yaw rate, target braking force of each wheel for realizing the target yaw rate is obtained, and target braking force of each wheel is attained through an actuator 5. Consequently, even with no detection of the neutral position when the engine is started, behavior control in accordance with a steering angle can be performed, detection of vehicle behavior is not required in calculation of the target yaw rate, and hunting is prevented from being also generated.

COPYRIGHT: (C)1998,JPO

THIS PAGE BLANK (USPTO)

(19)



Europäisches Patentamt
European Patent Office
Office européen des brevets



(11)

EP 0 799 755 A2

(12)

EUROPEAN PATENT APPLICATION

(43) Date of publication:
08.10.1997 Bulletin 1997/41

(51) Int Cl.⁶ B62D 15/02, B60G 17/015

(21) Application number: 97301578.7

(22) Date of filing: 10.03.1997

(84) Designated Contracting States:
DE FR GB

(30) Priority: 01.04.1996 US 625966

(71) Applicants:

- Ford Motor Company Limited
Brentwood, Essex CM13 3BY (GB)
Designated Contracting States:
GB
- FORD FRANCE S. A.
92506 Rueil-Malmaison Cédex (FR)
Designated Contracting States:
FR
- FORD-WERKE AKTIENGESELLSCHAFT
50735 Köln (DE)
Designated Contracting States:
DE

(72) Inventors:

- Madau, Dinu Petre
Dearborn, Michigan 48126 (US)
- Ashrafi, Behrouz
Dearborn, Michigan 48126 (US)

(74) Representative: Messulam, Alec Moses et al
A. Messulam & Co.
24 Broadway
Leigh-on-Sea Essex SS9 1BN (GB)

(54) Method for determining steering position of automotive steering mechanism

(57) A method for determining a steering wheel angle of a vehicular steering system includes determining a centre position for the steering sensor (20) output every time the vehicle is started. The method employs the use of a yaw sensor (17) for computing an estimate of the actual steering position so that a centre position may

be back computed to provide immediate and accurate steering position data using the steering sensor signal for controlling an automotive device (12). The accuracy of the initial estimates may be improved upon by implementing interim and final centre algorithms as vehicle operating characteristics permit.

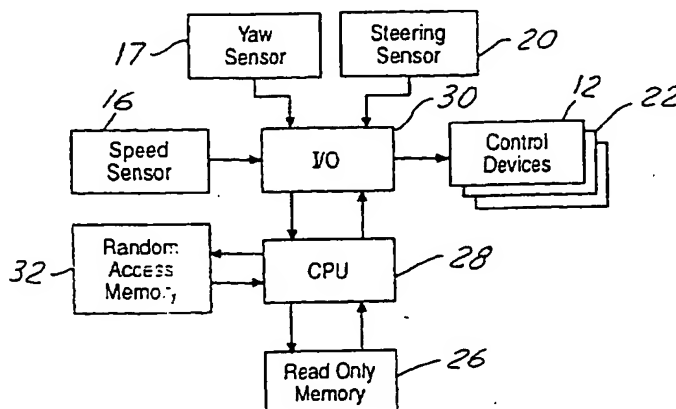


FIG. 4

EP 0 799 755 A2

Description

This invention relates to a method for determining the steering position of a vehicular steering mechanism. This method is useful for controlling a vehicular braking system and other automotive devices.

The use of steering angle sensors to provide steering input for the control of suspension units is commonly known. Systems employing fixed steering angle sensors are prone to failure due to calibration of the sensor. Also, such sensors are unable to compensate for steering system changes, such as wheel misalignment, road crown and cross wind compensation in addition to wear within the steering mechanism.

The steering sensor system disclosed in U.S. Patent 4,848,791, which is assigned to the assignee of the present invention, utilises a software program in which steering centre position is statistically determined over a fixed period of time sufficient to insure an accurate centre position. While this system eliminates the calibration problems associated with fixed sensors, the system described requires significant time during initial operation to converge on a centre position, thereby reducing the accuracy of the calculated instantaneous steering position.

Consequently, a greater emphasis has been placed on the ability of steering angle sensors to rapidly converge on a centre position. As an example, in the application of an interactive vehicle dynamics (IVD) system, in which the brakes may be independently actuated to assist the driver's ability to turn the motor vehicle, it has been deemed important to find the actual position of the steering wheel as rapidly as possible after start-up. This allows an IVD system to assist the driver to the fullest extent possible as early as possible in the operation of the vehicle. It would therefore be desirable to provide a steering angle sensor capable of reliably converging on a centre position in the first seconds of vehicle motion.

It is an object of the present invention to provide a method for rapidly determining the centre position of a vehicular steering mechanism each time the vehicle ignition is turned on.

In accordance with the present invention, a method for determining the steering position of an automotive steering mechanism to be used for controlling an automotive device comprises the following steps: counting steering position data from a steering angle sensor and generating a first signal therefrom representing rotational motion of the steering mechanism; measuring a yaw rate from a yaw rate sensor and producing a second signal therefrom representing a steering wheel angle computed from the yaw rate; determining a centre position estimate from the first signal and the second signal and generating a centre position signal therefrom; estimating an actual steering wheel angle from the first signal and the centre position signal and generating an estimated steering wheel angle signal therefrom; and controlling an automotive device using the estimated steering wheel angle signal.

The invention will now be described, by way of example, with reference to the accompanying drawings, in which:

FIG. 1 is a perspective drawing of a motor vehicle including a system according to the present invention. This figure shows various components of a system embodying the present invention;

FIG. 2 is a plan view, partially cut away, of a steering sensor comprising a component part of a system according to the present invention;

FIG. 3 is a cross sectional view of the steering sensor of the present invention taken along the line 3-3 of FIG. 2;

FIG. 4 is an overall system block diagram in accordance with an embodiment of this invention;

FIG. 5A illustrates the output waveforms of the detectors employed in the steering sensor illustrated in FIGS. 2 and 3 for clockwise rotation;

FIG. 5B illustrates the output waveforms of the detectors employed in the steering sensor illustrated in FIGS. 2 and 3 for counterclockwise rotation;

FIG. 6 is a truth table illustrating the outputs of detectors A and B shown in FIGS. 2-3 as the steering sensor of the present invention is rotated counterclockwise and clockwise;

FIGS. 7A, 7B and 7C are logic flow block diagrams in accordance with the principles of the present invention; and

FIG. 8 shows a time based plot of some variables generated during the execution of algorithms in accordance with the principles of the present invention.

As shown in FIG. 1, a method according to the present invention is intended for use with electronically controlled hydraulic braking systems and also steering gears typically found in automotive vehicles. The motor vehicle shown in FIG. 1 is equipped with electronically controlled hydraulic braking systems having controlled brake actuators 12 which cooperate with wheel and tire assemblies 10. These brake actuators may be constructed in a known manner such as that commonly employed on Ford Motor vehicles in use today. Those skilled in the art will appreciate in view of this disclosure that a method according to the present invention could be utilised in the control of other adjustable vehicular devices such as adjustable suspension units, hydraulic crossover suspension systems, variable volume air suspension springs, or variable stabiliser bars. Similarly, system according to the present invention could be employed with semi-active and active suspension devices.

The component parts of a system which may be used with the present invention are shown in FIGS. 1-4. Accord-

ingly, control module 14 receives inputs from steering sensor 20, speed sensor 16, yaw sensor 17 and brake sensor 18. Although not illustrated, height sensors and accelerometers could be employed with a suspension control system utilising the present invention. A system according to the present invention could, as previously noted, be used with braking systems or other automotive equipment with which it is necessary to know the position of the steering mechanism.

Those skilled in the art will appreciate in view of this disclosure that speed sensor 16 could comprise any of a variety of devices or systems employed in automotive vehicles. One type of automotive speed sensor suitable for use with a system according to the present invention comprises a speed module for receiving input from multiple speed sensors adapted to indicate the speed of the individual wheels. The speed module derives a longitudinal vehicle speed signal by combining the signals from the speed sensors. One such type of speed signal module is embodied in brake control modules presently used in Ford Motor Company vehicles. The individual wheel speeds are ascertained using pulse generators disposed at each wheel.

Referring to FIG. 4, a control module may output commands to brake actuators 12 (controlled devices 12, FIG. 4). Those skilled in the art will appreciate in view of this disclosure that the processor within the control module and its associated peripheral equipment could be structured according to several different architectures. In a preferred embodiment, however, the processor is configured so that a control program is sequentially read for each unit command from a read-only memory (ROM) 26 which stores preset control programs. Unit commands are executed by a central processing unit (CPU) 28. The processor integrally includes an input-output control circuit (I/O) 30 for exchanging data with external devices and a random access memory (RAM) 32 for temporarily holding data while the data are being processed.

Steering sensor 20, acting in conjunction with control module 14, includes means for measuring the excursion angle of the steering mechanism as a series of marker counts or steps measured from the initial position which the steering mechanism occupied when the system was activated by an operator keying on the ignition of the vehicle:

As shown in FIGS. 2 and 3, steering sensor 20 comprises shutter wheel 36 attached to steering shaft 38, which shaft rotates in unison with the steering wheel as the steering wheel is turned by the driver of the vehicle. Shutter wheel 36 has a plurality of apertures 40, in this case 48 in number, which apertures serve to trigger the activity of spaced apart detectors A and B as the shutter wheel is rotated with the steering system of the vehicle. Detectors A and B detect movement of the shutter wheel. Because there are 48 apertures contained within shutter wheel 36, the steering sensor provides a signal 192 times during one revolution of the steering wheel and as a result each of the 192 counts or steps indicates 1.875 degrees of rotation of the steering mechanism.

As shown in FIG. 3, each of detectors A and B includes a light emitting diode (LED) 42 and a photo diode 44. The combination of the LED and photo diode is used to detect movement of shutter wheel 36 and, hence, the steering mechanism. This is possible because the photo diodes have two states; i.e., they are bi-stable. A conducting state occurs whenever light from the paired LED passes through an aperture 40 in the shutter wheel and impinges upon the photo diode. The output of the detector circuit then rises to approximately 10 volts. A non-conducting state exists whenever the shutter wheel blocks the transmission of light between the LED and the photo diode.

As shown in FIG. 5A, clockwise rotation of shutter wheel 36 produces a waveform pattern for the detectors in which detector A undergoes its transition prior to detector B. In other words, detector A leads detector B. This results from the spacing between the detectors, shown as dimension D in FIG. 2 with respect to the spacing between the apertures shown as dimension S in FIG. 2. More precisely, dimension D is 1.75 times dimension S. As shown in FIG. 5B, counterclockwise rotation of the steering sensor produces a waveform pattern for the detectors in which detector A undergoes its transition after detector B and detector A thus lags detector B. The outputs of detectors A and B are fed into the control module, and in this manner the control module is allowed to track the direction of the steering mechanism's movement. Increasing the number of apertures on shutter wheel 36 improves the resolution of the sensor. The present invention allows a significant increase in the number of apertures while maintaining the ability to reject meaningless steering wheel excursions (by determining a finer resolution).

FIG. 6 is a tabulation of the waveforms shown in FIGS. 5A and 5B in a digital format. In conventional fashion, the approximately 10 volts maximum output of the detectors is treated as a logical "1", while the zero output state is treated as a logical "0". FIG. 6 shows each of the possible logic pair states which could be output by detectors A and B. The pairs are arranged in the order in which they will be received by the control module for both counterclockwise and clockwise rotation. As seen in FIG. 6, counterclockwise rotation is read from the bottom of the figure to the upper part of the figure with clockwise rotation being read from the top of the tabulation to the lower part of the tabulation. Thus, it may be realised that detector devices A and B generate a cyclical series of two-bit, binary coded data (SWA), corresponding to a finite amount of rotation of steering shaft 38 relative to the initial position of the steering mechanism at start-up. The use of these counts to determine an accurate estimate of the actual centre position of the steering mechanism (SWACENTER) and a corresponding estimate of the actual steering angle (SWAEST) of the vehicle in a system according to the present invention will be explained in conjunction with FIGS. 7A, 7B and 7C.

Generally, the present invention provides an improvement in determining the estimated centre position necessary

for calculating the steering position from the raw steering data (SWA) obtained from the steering sensor 20. It should be recognised that the difference between the measured steering data (SWA) and the actual steering angle is the difference between the actual steering wheel angle at vehicle start up and the steering wheel angle when travelling straight ahead (ideally zero.) Unfortunately, it cannot be guaranteed that a vehicle will always be started with the steering mechanism in the straight ahead position. Therefore, it becomes necessary to estimate the location of the centre position.

The present invention determines the location of the centre position according to one of three techniques, an initial centre algorithm, an interim centre algorithm and a final centre algorithm. The primary difference among the algorithms is the speed with which they converge on a centre position estimate and the accuracy or reliability of this centre position estimate. Initially, when the operator first starts the vehicle, the initial centre algorithm is used to provide a very rapid estimate of the centre position. Then, when predetermined vehicle operating characteristics are satisfied, the processor switches over and uses the interim centre algorithm. In the preferred embodiment, the processor makes this switch when it senses the steering mechanism is substantially positioned in the estimated centre position. Once the switch has been made, the processor will not return to the initial centre algorithm until the ignition is switched from off to on.

The processor will refine the estimate of the centre position using the interim centre algorithm until further operating characteristics are satisfied. When these characteristics are satisfied, the processor switches to the final centre algorithm for providing the final adjustments to the centre position estimate. Similarly, the processor will not exit the final centre algorithm until the ignition is switched off. The operation of these three centre position estimating algorithms and how they are integrated into a system will be described below.

Turning now to figure 7A, operation of a system in accordance with the present invention will be further explained. At block 100 the processor starts the illustrated algorithm when the operator keys on the vehicle ignition. The processor then moves to block 102 where the various sensors are read and their data input to the processor. If this is the first time through the algorithm all of the variables are initialised with predetermined values. The processor then steps to block 104 where maximum yaw velocity and acceleration limits (MaxYawV, MaxYawAcc) are set depending on the vehicle longitudinal speed read at block 102. The processor then proceeds to block 106 and calculates the yaw acceleration (YawAcc) and other variables from the yaw rate data read at block 102. The processor then advances to block 108.

At block 108, the processor updates minimum and maximum steering wheel angles (SWAMIN, SWAMAX) experienced thus far by comparing their present values with the present steering wheel angle data (SWA). The processor then advances to block 110 and calculates a quantitative straight path indicator (SWAPOC) of the likelihood that the vehicle is travelling in a straight line. SWAPOC ranges from 0 to 100, with 100 indicating a strong likelihood that the vehicle is travelling straight. In the presently preferred embodiment SWAPOC is calculated according to one of two formulas. First, the operating characteristics of the motor vehicle are assessed to determine which of two formulas to use to update SWAPOC. If the longitudinal velocity of the vehicle is greater than a predetermined velocity, which in the presently preferred embodiment is 7 kph, and a flag representing the status of an IVD system indicates that the IVD system is not active and absolute values of the yaw velocity and acceleration are less than predetermined limits, MaxYawV and MaxYawAcc, respectively, a first formula will be used. If these conditions are satisfied, the processor uses the first relationship to increase the value for SWAPOC, indicating that the vehicle is likely operating in a straight path. The assumption is that if the vehicle operates under these conditions long enough, then the vehicle is travelling straight. If, on the other hand, these conditions are not satisfied, then the processor uses a second relationship to decrease SWAPOC. In the presently preferred embodiment, the first relationship takes the following form:

$$SWAPOC = 20 + SWAPOC * 0.80$$

and the second relationship takes the following form:

$$SWAPOC = SWAPOC * .80$$

The processor then proceeds to conditional block 112.

At conditional block 112, the processor ascertains whether or not the final centre routine has been started by checking the status of a flag, FOUNDCENTRE. At the outset, the FOUNDCENTRE flag will be false, or 0, and the processor will proceed to conditional block 114. At conditional block 114 the processor evaluates the indicator SWAPOC to determine whether or not SWAPOC has attained a value greater than 95. Similarly, at the outset SWAPOC will be less than 95 and the processor will proceed through advance block 115 to block 116.

Referring now to FIG. 7A, the processor evaluates several vehicle conditions at the conditional block 116 to determine whether or not the vehicle is operating in a state for which a centre position should be estimated. In the presently

preferred embodiment, this conditional block is satisfied by the existence of the following conditions: the ignition has been switched on long enough for the yaw sensor to power-up and stabilise; the vehicle is travelling at less than a predetermined minimum, which in the present invention is 7 kph; and the IVD system is inactive. If any one of these conditions is not satisfied the processor forgoes updating the centre position and proceeds via advance block 119 to block 118.

Referring back to FIG. 7A, at block 118 the processor uses the existing estimate of SWACENTER to determine the estimate of the steering angle, SWAEST according to the following relationship:

$$SWAEST = SWA - SWACENTER$$

where SWA is the uncentred signal generated by the steering wheel angle sensor. On the first pass through, if the conditions in block 116 were not satisfied, SWAEST would assume a value equal to SWA since SWACENTER would still have its initialised value of 0. The processor then proceeds to block 122 where the present value of the yaw rate signal, YawVRaw, is stored in memory as YawVRawZ1 for use in first order filtering devices. The processor then proceeds to block 102 via advance block 123.

At block 102 the sensors are read and the variables are updated based on the new data. The processor proceeds through blocks 104, 106, 108 and 110 as previously described. At conditional block 112, assume FOUNDCENTRE remains "false" and the processor proceeds to block 114. Also assume that SWAPOC has not yet exceeded a value of 95. Referring now to FIG. 7B, the processor proceeds via advance block 115 to conditional block 116, where the processor will once again assess the operating characteristics of the vehicle. Assume this time the characteristics described above are satisfied and the processor proceeds to block 124.

At block 124, the processor calculates the steering angle of the front tires according to the following relationship:

$$\delta = \frac{r}{U} \left(L + \frac{K_{us}}{g} U^2 \right)$$

where:

- δ = the steered angle of the steerable tires;
- r = the yaw rate of the vehicle;
- U = the longitudinal velocity of the motor vehicle;
- L = the distance from the front axle to the rear axle;
- K_{us} = the understeer coefficient for the steered wheel suspension;
- g = gravitational constant.

Knowing the steered angle of the tires, δ , the processor can compute a yaw measurement based steering wheel angle, SWAFromYAW. At block 126 the processor calculates SWAFromYAW according to the following relationship:

$$SWAFromYAW = C * KSteer2SWA * \delta$$

where:

SWAFromYAW = the steering wheel angle computed from yaw measurement data;

C = conversion constant from radians to degrees;

$KSteer2SWA$ = steering ratio, a constant dependent on the steering mechanism and steering geometry.

It should be noted that in the preferred embodiment it has been found advantageous to provide unique steering ratio constants for right hand turns versus left hand turns, specifically for vehicles having non-symmetric steering mechanisms or geometry. With this information the processor proceeds to conditional block 128.

At conditional block 128, the processor determines whether the absolute value of SWAFromYAW is less than a predetermined limit, SWAFromYAWlimit. This predetermined limit represents boundaries within which a steering angle would be considered to represent straight line travel. For instance, the predetermined limit could be set to 5 degrees. If the absolute value of SWAFromYAW is less than 5 degrees, then the processor will assume the vehicle is going

straight or transitioning through the straight line steer position. The first time this occurs is referred to an "initial crossing". A crossing refers to the crossing from a non-zero steering position into a boundary representative of substantially straight ahead driving, or zero steering angle. The crossing may also be referred to as a zero crossing. Assuming that the absolute value SWAFromYAW is greater than SWAFromYAWlimit, the processor proceeds to block 132 via advance block 129.

Referring now to FIG. 7C, the processor sets the initial centre flag, INITIALCENTRE, equal to "true" or "1" at block 132 to indicate that the processor has started the initial centre algorithm. The initial centre algorithm first determines if the present steering event is greater than a predetermined minimum. It has been observed that SWACENTER values calculated when steering wheel angles are less than 180 degrees are more accurate than values calculated when the steering wheel angles are greater than 180 degrees. Therefore, it is advantageous to use data taken during steering events having steering wheel angles less than 180 degrees. The present embodiment of the initial centre algorithm benefits from this observation.

At conditional block 134 the processor evaluates the steering angle calculated from the yaw data, SWAFromYAW to determine whether it is less than 180 degrees. Assuming SWAFromYAW is not less than 180 degrees, the processor proceeds to conditional block 135. There, the processor checks a counter, FSETTLE180, to determine whether the processor has calculated SWACENTER using SWAFromYAW data of less than 180 degrees. If FSETTLE180 is greater than zero, the processor skips to block 118 via advance block 119 where SWAEST is updated using the existing SWACENTER value. This prevents the processor from recalculating SWACENTER if it has been calculated using SWAFromYAW data of less than 180 degrees. If FSETTLE180 is equal to 0, then the processor continues to conditional block 137.

At block 137, the processor determines whether SWAFromYAW is less than 360 degrees. This is necessary because it has been determined in practice that for very large steering angles, a more accurate SWACENTER can be obtained if a unique value is used for the steering ratio, KSteer2SWA. Assuming SWAFromYAW is not less than 360 degrees, the processor will proceed to conditional block 143. There, the processor checks another counter, FSETTLE500, which counts the number of times the initial centre algorithm calculates SWACENTER when SWAFromYAW is greater than or equal to 180 degrees, but less than 360 degrees. Here, SWACENTER will only be calculated if FSETTLE500 is equal to zero, indicating that SWACENTER has not been calculated using data less than 360 degrees. Once FSETTLE500 is greater than zero, SWACENTER will not be calculated using data greater than 360 degrees. Assuming FSETTLE500 is equal to zero, the processor proceeds to block 144. At block 144 KSteer2SWA is reset and the processor calculates a new SWAFromYAW and corresponding SWACENTER at block 146. SWACENTER is calculated according to the following relationship:

$$\text{SWACENTER} = \text{SWADynamic} - \text{SWAFromYAW}$$

where SWADynamic represents the SWA signal from the steering angle sensor after it has been passed through a second order filter. At block 148 SWACENTER is filtered by a first order filter and SWACENTREold is set to equal the new filtered SWACENTER. At this point the processor proceeds to block 118 via advance block 119. The processor then proceeds to calculate SWAEST and return back through the loop to ultimately end up in the initial centre routine again, assuming that SWAPOC had not exceeded 95 or SWAFromYAW had not fallen below SWAFromYAWlimit.

Assuming this time that SWAFromYAW is between 180 degrees and 360 degrees and FSETTLE180 equals zero, the processor proceeds to conditional block 139. At block 139, if FSETTLE500 is greater than 300 the processor would proceed to block 118 via advance block 119, indicating that no additional calculations need be made using this range of data. If FSETTLE500 is less than 300, the processor proceeds to block 138, where FSETTLE500 is incremented and SWACENTER is calculated according to the following relationship:

$$\text{SWACENTER} = \text{SWADynamic} - \text{SWAFromYAW}$$

where the variables are the same as those discussed in reference to block 146. At block 140 the processor filters the SWACENTER signal through a first order filter and updates SWACENTREold with the new SWACENTER value. The processor then proceeds to block 118 via advance block 119 where SWAEST is updated using the new SWACENTER value. Assuming that SWAPOC had not exceeded 95 or SWAFromYAW had not fallen below SWAFromYAWlimit, the processor returns to the initial centre algorithm.

Now, assume that SWAFromYAW is less than 180 degrees. The processor proceeds to conditional block 150 to evaluate FSETTLE180, to determine if it is below a predetermined limit. This counter serves two purposes. First, once the initial centre algorithm makes its first centre position estimate using data acquired with SWAFromYAW less than 180 degrees, the processor increments the counter and the routine will not recalculate SWACENTER when SWAFromYAW

mYAW is greater than or equal to 180 degrees. The second purpose eliminates redundant computation. It has been observed that the SWACENTER does not improve after a predetermined number of calculations, that is to say it converges within the limits of accuracy of the initial centre algorithm. In the presently preferred embodiment, this corresponds to 300 iterations. If FSETTLE180 is greater than 300, the processor proceeds directly to block 118 via advance block 119 preventing any further updating of SWACENTER by the initial centre algorithm. If FSETTLE180 is less than 300, the processor proceeds to block 151, where FSETTLE180 is incremented and SWACENTER is calculated according to the following relationship:

$$\text{SWACENTER} = \text{SWADynamic} - \text{SWAFromYAW}$$

where the variables are the same as those discussed in reference to block 146. At block 152 the processor filters SWACENTER signal through a first order filter and updates SWACENTREold with the new SWACENTER value. The processor then proceeds to block 118 via advance block 119 where SWAEST is updated using the new SWACENTER value. The processor will continue in the initial centre algorithm until SWAPOC becomes greater than 95 or the SWAFromYAW becomes less than the SWAFromYAWlimit at block 128.

Referring back now to FIG. 7B, assuming SWAPOC has not attained a value of 95, the interim centre algorithm is initially entered at block 154 when the absolute value of SWAFromYAW becomes less than the SWAFromYAWlimit as tested at conditional block 128. It should be noted that additional criteria may be used to determine the stability of the zero crossing. For instance, it may be advantageous to determine the frequency of zero crossings. If the frequency exceeds a threshold, the zero crossing data may be rejected. If these conditions are satisfied, then this corresponds to the initial centre crossing. At conditional block 154, the processor checks a flag, FIRSTSWADYN, to determine if this is the initial centre crossing. If FIRSTSWADYN is "true" or "1", then this pass represents the initial centre crossing and the processor proceeds to block 156. At block 156, the processor sets the flag, FIRSTSWADYN, to "false" or "0", indicating that subsequent centre crossings will not be the initial centre crossing. The processor also sets another flag, INTERIMCENTRE, to "1" to indicate that the interim centre algorithm has been entered, which will prevent the processor from returning to the initial centre algorithm. The processor then sets SWACENTREMIN and SWACENTREMAX to the current value of SWADYNAMIC. At this point SWADYNAMIC represents the best estimate of SWACENTER and therefore it is also the most accurate boundaries for future SWACENTER filtering.

The processor then proceeds to block 160 where a variable, SWACTRFLTIN, for use in a first order filter, is calculated according to the following relationship:

$$\text{SWACTRFLTIN} = \frac{\text{SWACENTERMAX} + \text{SWACENTERMIN}}{2}$$

The variable SWACTRFLTIN enables the use of a dynamic first order filter, which, in essence ensures that the filtered SWACENTER signal falls between the boundaries of SWACENTREMIN and SWACENTREMAX. This filtering occurs at block 162. The processor then proceeds to block 118 via advance block 119.

The processor will continue to determine and refine SWACENTER using the interim centre algorithm as long as SWAPOC is less than 95 and the final centre algorithm has not been entered. It should be noted that the interim centre algorithm updates SWACENTER only when the system is involved in a zero crossing, as determined at block 128. Otherwise, the processor proceeds using the previously determined SWACENTER via advance block 129. Assuming the absolute value SWAFromYAW is less than SWAFromYAWlimit at block 128, the processor proceeds from conditional block 154 to block 171 where SWACENTREMIN and SWACENTREMAX are updated using the present values of SWADYNAMIC, but only if they provide a tighter set of boundaries than the previous SWACENTREMIN and SWACENTREMAX. The processor then proceeds through block 160 as described above. It should be noted that it may be desirable to incorporate a delay loop in the interim centre algorithm to eliminate redundant computations while the steering system is operated within a single zero crossing event. The interim centre algorithm is repeated until SWAPOC at logic block 114 exceeds 95.

Referring now to figure 7A, assuming that SWAPOC is greater than 95, the processor will be directed to block 174 by block 114. At block 174 the final centre algorithm flag, FOUNDCENTRE, will be set "true" or "1", indicating that the final centre algorithm has been entered. The processor will not return to the interim centre algorithm until after the ignition key is turned off and then on. The processor also sets SWACENTER equal to the current reading of SWA. As SWAPOC is now greater than 95, the assumption is that the vehicle is travelling along a straight path. The processor is then directed via advance block 119 to block 118 where SWAEST will be once again determined in the usual fashion. The processor will once again return to logic block 112 where the FOUNDCENTRE flag will indicate that the final centre algorithm has been initiated and the processor will be directed to logic block 176. At block 176, the processor determines if SWAPOC is greater than 95. In the event SWAPOC is greater than 95 the processor will proceed to block 178 where

SWACENTER is filtered with the current SWA by a first order filter using the previous SWACENTER data. If SWAPOC is less than 95, the processor proceeds to block 118 and calculates SWAEST using the existing value of SWACENTER and the current SWA.

Referring now to FIG. 8, a plot illustrates values of the several variables as the processor proceeds through each of the three algorithms described above. It should be noted that the scenario depicted is for illustrative purposes and does not reflect actual performance of the present invention as one would anticipate under normal driving conditions. However, the plot does illustrate the rapid convergence and unparalleled accuracy for a sample worst case scenario. Generally, convergence will occur almost simultaneously with the vehicle attaining 7 kph. The ordinate on the left of the plot indicates the actual steering wheel angle, which is what the invention is trying to determine. The ordinate on the right indicates the signal generated by the steering wheel sensor, SWA. It should be noted that the challenge arises from having a non-calibrated signal, SWA, generated by the steering wheel sensor. That is, every time the vehicle is keyed on, the sensor indicates a zero value output for the present steering position. This must be calibrated by a process such as the present invention to obtain the actual steering wheel angle as indicated by the left ordinate.

The initial portion, identified as "A" along the time axis, refers to the initial centre algorithm. It can be seen that, initially, the steering wheel angle exceeds 360 degrees. By the end of A, the system has calculated a value for SWACENTER. This means the system has an estimate for controlling the vehicle dynamics shortly after keying the ignition on. The most significant delay represents the time the vehicle took to get to 7 kph.

As the steering wheel angle drops below 180, as indicated during A₂, the processor recalculates and reconverges SWACENTER, as can be seen by the slight "ripple" in the SWACENTER plot. During A the steering system encounters the first centre crossing. This triggers the interim centre algorithm, shown as portion B along the time axis. The processor adjusts SWACENTREMIN and SWACENTREMAX from their initialised values. These values are maintained until the start of B₂, where the next crossing occurs. As can be seen, at each crossing B₁, B₂, B₃, etc. minor refinements in SWACENTREMIN and SWACENTREMAX are made, resulting in small changes in the filter through which SWACENTER is processed. Ultimately, SWAPOC reaches a value exceeding 95 and the processor enters the final centre algorithm. Due to the scale of the drawing, SWAPOC appears to be a step function, however it is actually gradually built up through successive iterations by the processor. At the very beginning of portion C, SWACENTER is set equal to SWA, which appears in the present example to be approximately 360 degrees. Subsequently, SWAPOC drops below 95 for a period, C₁. The processor does not update SWACENTER again until SWAPOC exceeds 95, which occurs several times during period C₂. The processor continues in the final centre algorithm until the vehicle ignition is keyed off. Various modifications and variations will no doubt occur to those skilled in the art to which this invention pertains. For example, the particular sensors used in conjunction with the disclosed system may be varied from those herein and the system may be operated according to various control constants and with other values for the variables contained within the calculational scheme described herein.

Claims

1. A method for determining a steering wheel angle of an automotive steering mechanism and controlling an automotive device, comprising the steps of:
 - counting steering position data from a steering angle sensor (20) and generating a first signal therefrom representing rotational motion of the steering mechanism;
 - measuring a yaw rate from a yaw rate sensor (17) and producing a second signal therefrom representing a steering wheel angle computed from said yaw rate;
 - determining a centre position estimate from said first signal and said second signal and generating a centre position signal therefrom;
 - estimating an actual steering wheel angle from said first signal and said centre position signal and generating an estimated steering wheel angle signal therefrom; and
 - controlling an automotive device (12) using said estimated steering wheel angle signal.
2. A method according to claim 1, wherein the centre position estimate is determined in accordance with a first predetermined algorithm when said second signal is outside of a predetermined boundary and in accordance with a second predetermined algorithm when said second signal is within said predetermined boundary.
3. A method according to claim 1, including updating a straight path indicator using one of two formulas selected based on an evaluation of a predetermined group of vehicle operating characteristics; and
 - wherein the centre position estimate is determined in accordance with a first predetermined algorithm when said second signal is outside of a predetermined boundary limit and in accordance with a second predetermined

algorithm when said second signal is within said predetermined boundary limit and in accordance to a third predetermined algorithm when said straight path indicator exceeds a predetermined value.

4. A method according to claim 1, 2 or 3, wherein said step of producing a second signal representing a steering wheel angle includes obtaining said second signal by the following relationship:

$$\text{SWAFromYAW} = C * K\text{Steer2SWA} * \delta$$

where:

SWAFromYAW = the calculated steering wheel angle;

C = conversion constant from radians to degrees;

KSteer2SWA = steering ratio, a constant dependent on the steering mechanism and steering geometry; and

δ = the steered angle of the steerable tires as determined from the yaw data.

5. A method according to claim 1, 2 or 3, wherein said step of generating a centre position signal includes evaluating the following relationship:

$$\text{SWACENTER} = \text{SWADynamic} - \text{SWAFromYAW}$$

where:

SWACENTER = calculated centre position;

SWADynamic = a signal generated from the steering angle sensor output;

SWAFromYAW = a calculated steering wheel angle computed using vehicle yaw.

6. A method according to claim 1, 2 or 3, wherein said step of generating an estimated steering wheel angle signal includes evaluating the following relationship:

$$\text{SWAEST} = \text{SWA} - \text{SWACENTER}$$

where:

SWAEST = estimated steering wheel angle;

SWA = is the signal generated by the steering wheel angle sensor;

SWACENTER = calculated centre position.

7. A method according to claims 2 or 3, wherein said step of determining a centre position estimate in accordance with a first predetermined algorithm further comprises the following steps:

calculating said centre position signal using a first range of data when said second signal exceeds a predetermined limit; and

recalculating said centre position signal using a second range of data only after said second signal is less than said predetermined limit.

8. A method according to claims 2 or 3, wherein said step of determining a centre position estimate in accordance with a second predetermined algorithm further comprises updating said centre position signal only if said second signal is within said predetermined boundary.

9. A method according to claim 3, wherein said step of determining a centre position estimate in accordance with a third predetermined algorithm further comprises only updating said centre position signal when said straight path indicator exceeds a predetermined value once said predetermined value has been exceeded a first time.

10. A method according to claim 3, wherein said vehicle operating characteristics include vehicle longitudinal velocity, yaw rate and yaw acceleration.

11. A method according to claim 3, wherein said step of updating a straight path indicator further comprises the following steps:

reducing said straight path indicator when said any one of said vehicle operating characteristics do not exceed a predetermined minimum; and
increasing said straight path indicator when said vehicle operating characteristics equal or exceed said predetermined minimums.

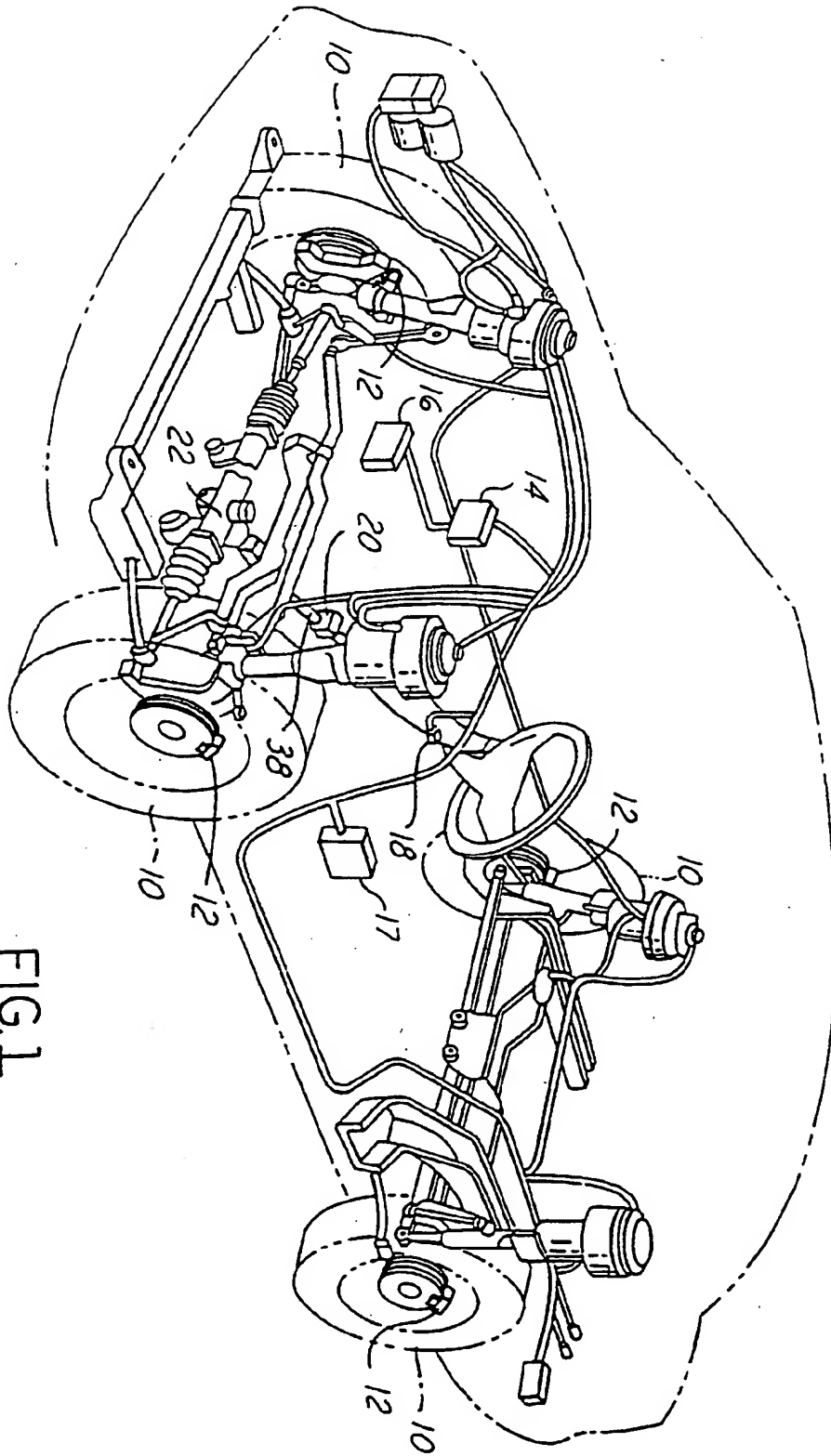
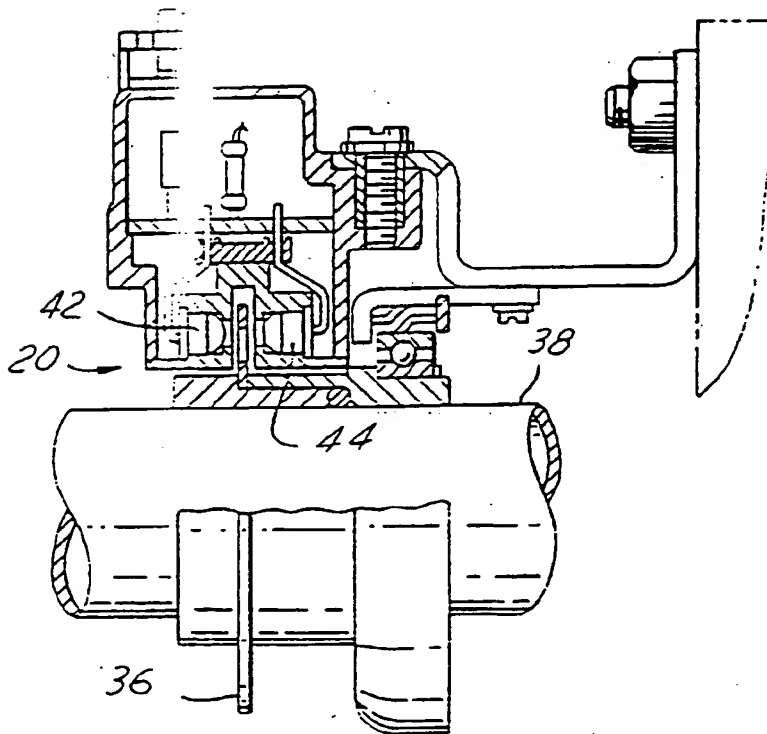
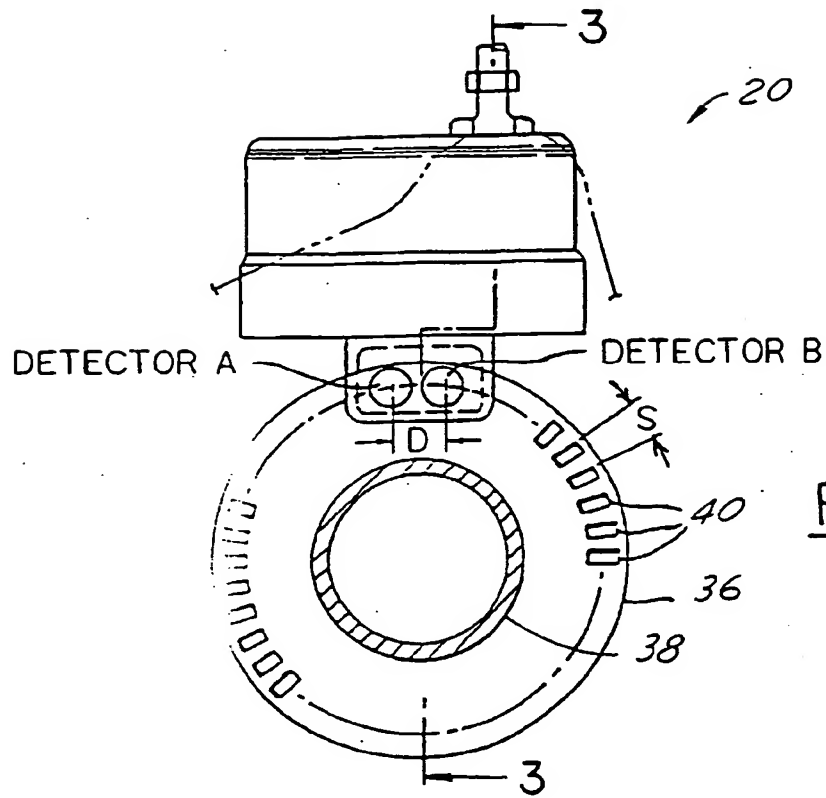


FIG. 1



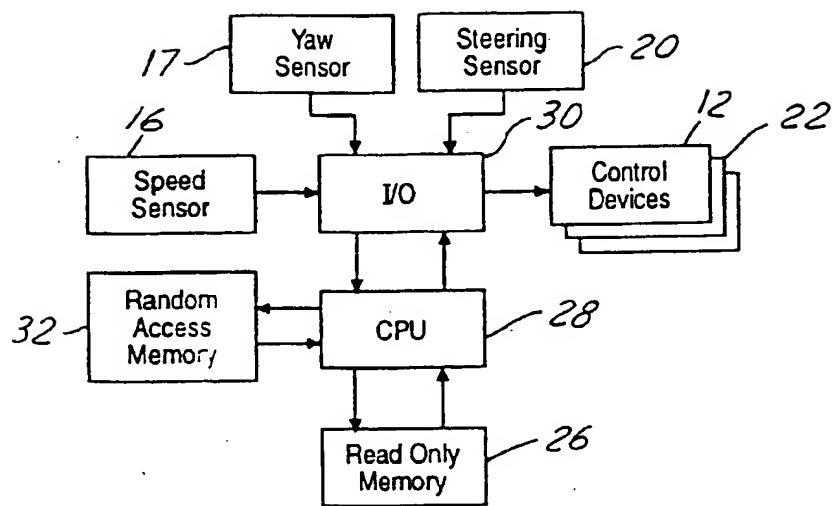


FIG. 4

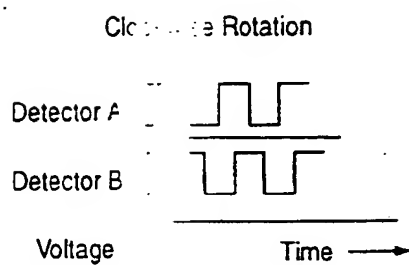


FIG. 5A

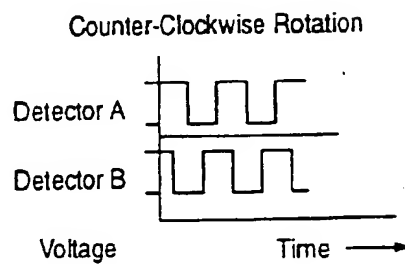


FIG. 5B

	Detector A	Detector B	
Counter-Clockwise Rotation	0	0	Clockwise Rotation
	1	0	
	1	1	
	0	1	
	0	0	
	1	0	

FIG. 6

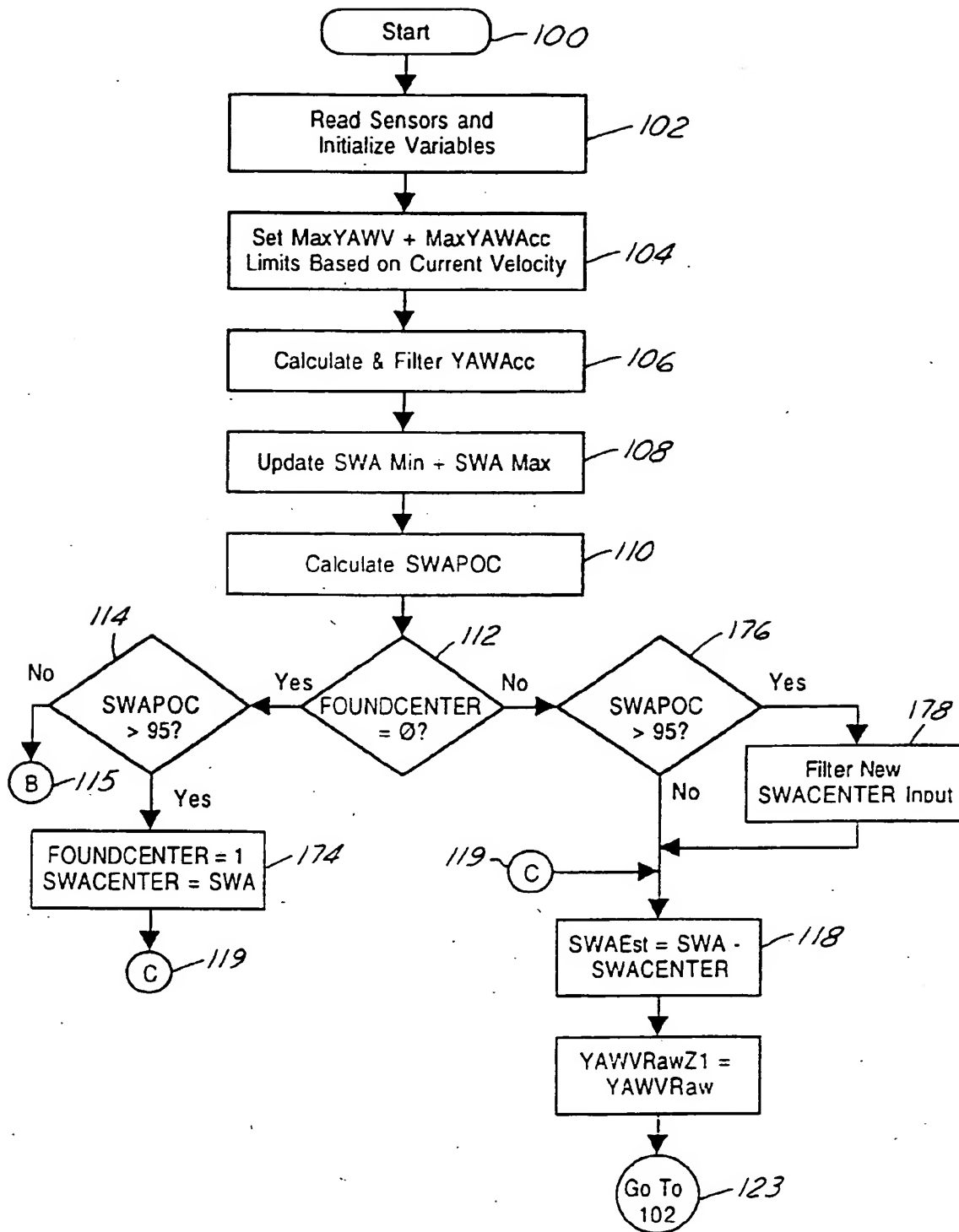
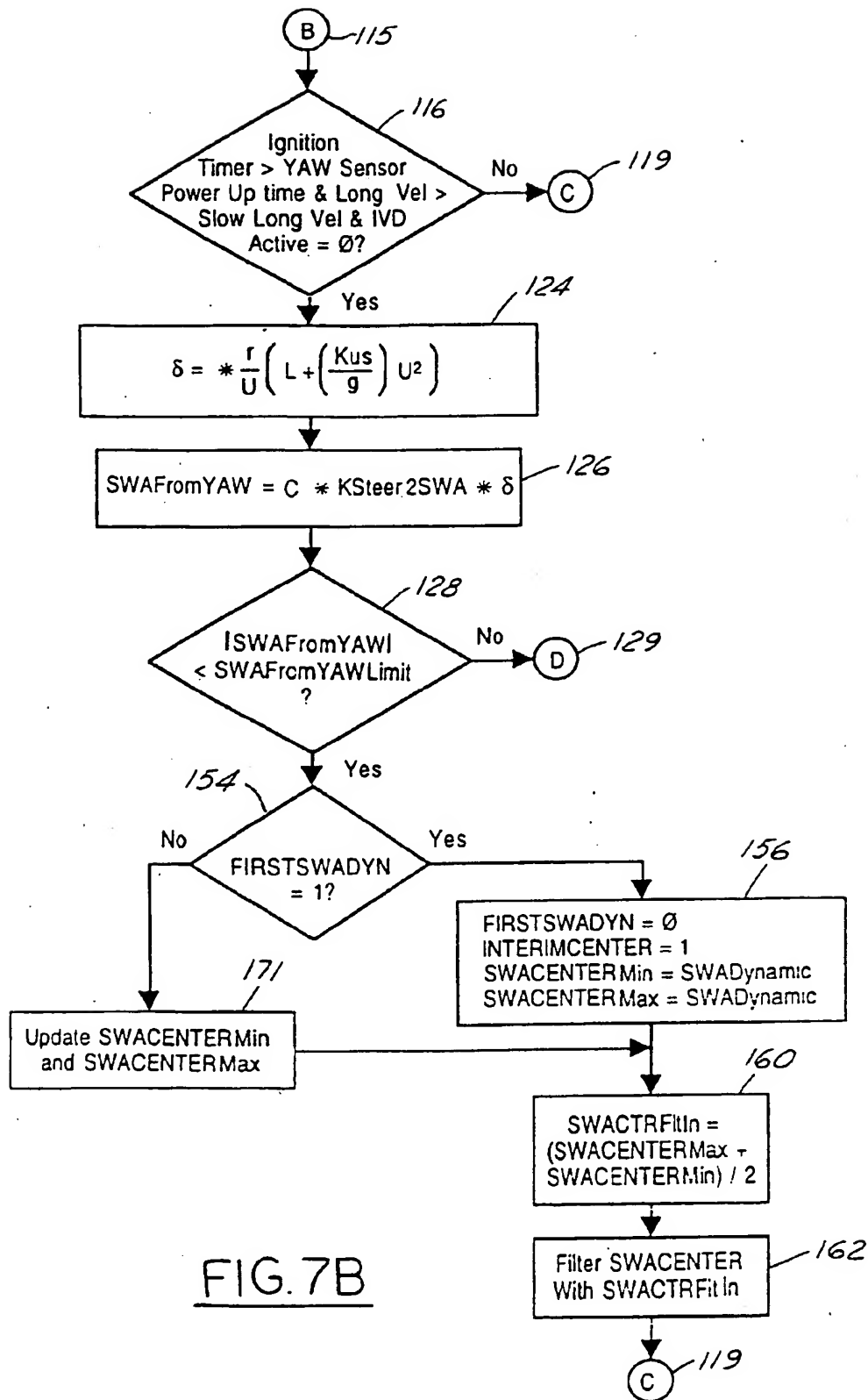


FIG. 7A



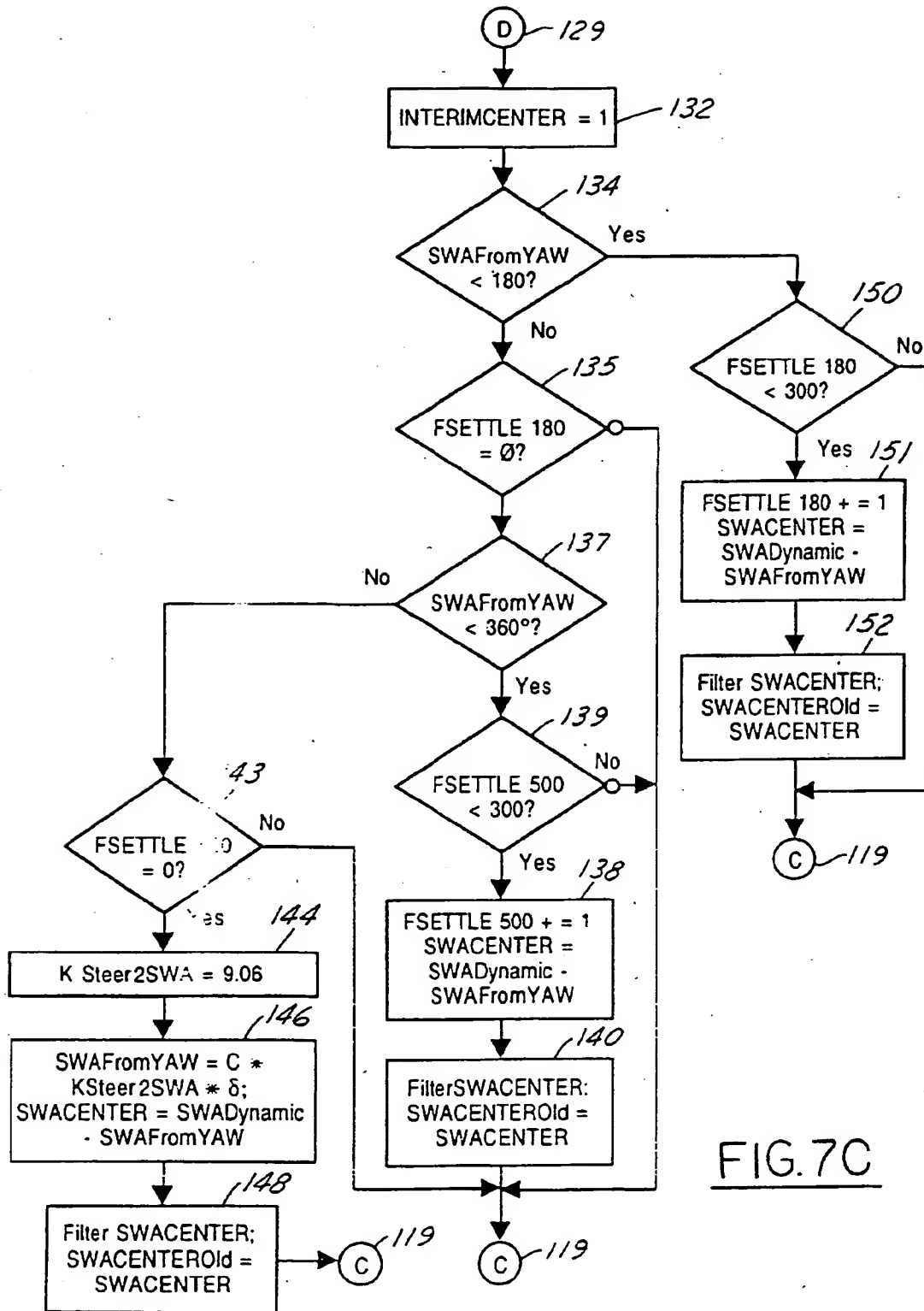


FIG. 7C

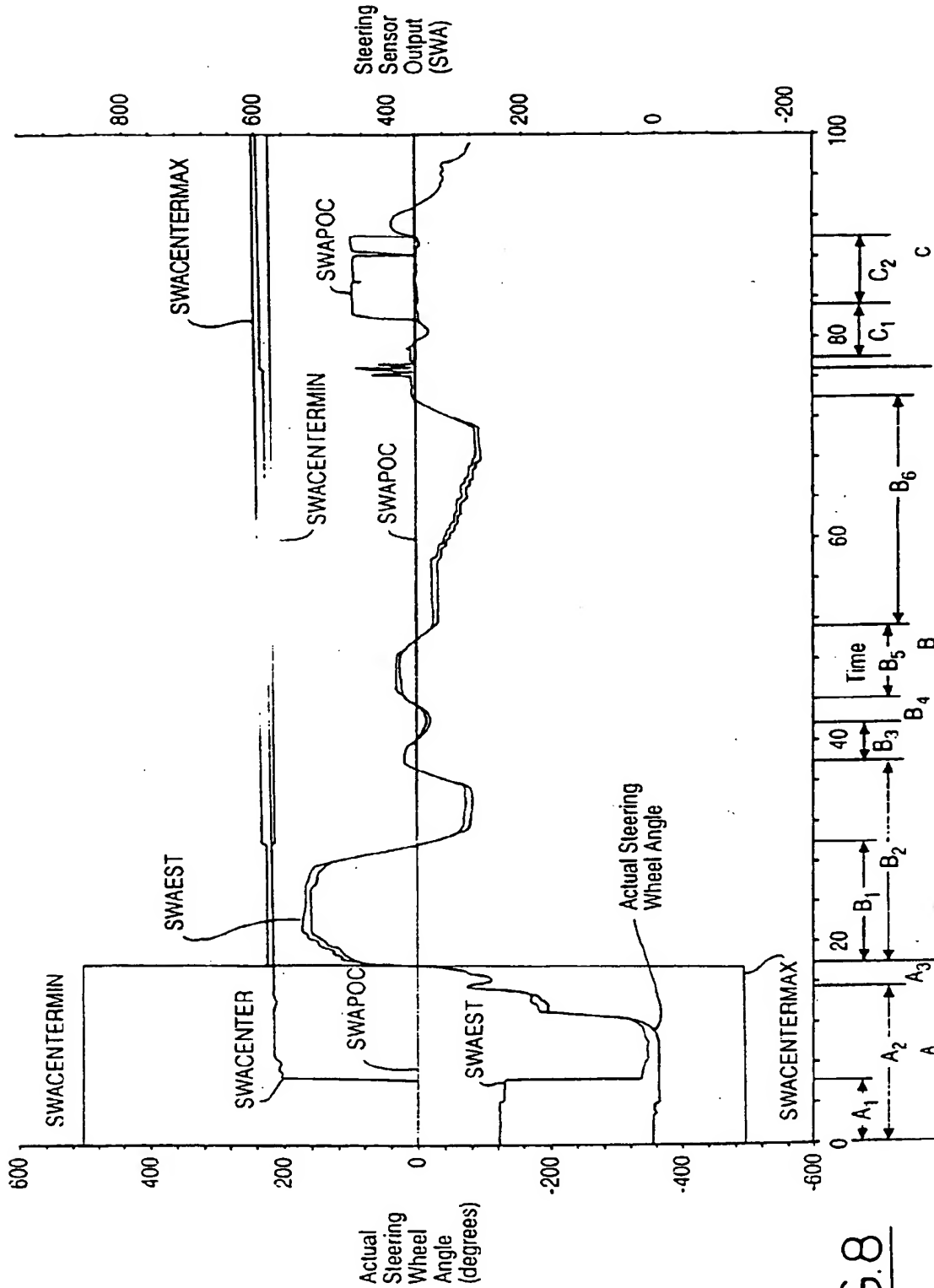


FIG.8

1944-1945

(19)



Europäisches Patentamt
European Patent Office
Office européen des brevets



(11)

EP 0 799 755 A3

(12)

EUROPEAN PATENT APPLICATION

(88) Date of publication A3:
29.03.2000 Bulletin 2000/13

(51) Int Cl.7: **B62D 15/02, B60G 17/015**

(43) Date of publication A2:
08.10.1997 Bulletin 1997/41

(21) Application number: **97301578.7**

(22) Date of filing: **10.03.1997**

(84) Designated Contracting States:
DE FR GB

(30) Priority: **01.04.1996 US 625966**

(71) Applicants:

- **Ford Motor Company Limited**
Brentwood, Essex CM13 3BY (GB)
Designated Contracting States:
GB
- **FORD FRANCE S. A.**
92506 Rueil-Malmaison Cédex (FR)
Designated Contracting States:
FR
- **FORD-WERKE AKTIENGESELLSCHAFT**
50735 Köln (DE)
Designated Contracting States:
DE

(72) Inventors:

- **Madau, Dinu Petre**
Dearborn, Michigan 48126 (US)
- **Ashrafi, Behrouz**
Dearborn, Michigan 48126 (US)

(74) Representative: **Messulam, Alec Moses et al**
A. Messulam & Co.
24 Broadway
Leigh-on-Sea Essex SS9 1BN (GB)

(54) Method for determining steering position of automotive steering mechanism

(57) A method for determining a steering wheel angle of a vehicular steering system includes determining a centre position for the steering sensor (20) output every time the vehicle is started. The method employs the use of a yaw sensor (17) for computing an estimate of the actual steering position so that a centre position may

be back computed to provide immediate and accurate steering position data using the steering sensor signal for controlling an automotive device (12). The accuracy of the initial estimates may be improved upon by implementing interim and final centre algorithms as vehicle operating characteristics permit.

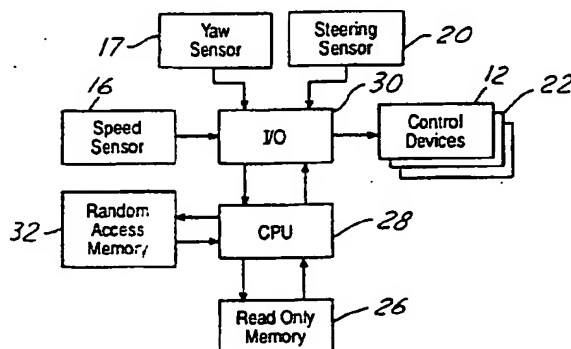


FIG. 4

EP 0 799 755 A3



European Patent
Office

EUROPEAN SEARCH REPORT

Application Number
EP 97 30 1578

DOCUMENTS CONSIDERED TO BE RELEVANT			
Category	Citation of document with indication, where appropriate, of relevant passages	Relevant to claim	CLASSIFICATION OF THE APPLICATION (Int.Cl.6)
X	EP 0 353 995 A (HONDA) 7 February 1990 (1990-02-07) * abstract: figure 1 *	1	B62D15/02 B60G17/015
X	PATENT ABSTRACTS OF JAPAN vol. 17, no. 123 (M-1380), 15 March 1993 (1993-03-15) -& JP 04 306177 A (TOYOTA), 25 October 1992 (1992-10-28) * abstract: figures 1-4 *	1	
A	PATENT ABSTRACTS OF JAPAN vol. 14, no. 384 (M-1013), 20 August 1990 (1990-08-20) & JP 02 144262 A (TOYOTA), 4 June 1990 (1990-06-04) * abstract *	1,3,10	
A	US 5 422 810 A (BRUNNING ET AL.) 6 June 1995 (1995-06-06) * the whole document *	1,3,10	
A	EP 0 590 576 A (HONDA) 6 April 1994 (1994-04-06) * page 9, line 27 - line 49 *	1	B62D B60G
A	DE 41 15 716 A (NISSAN) 23 January 1992 (1992-01-23) * abstract; figures *	1	
D,A	US 4 848 791 A (BRIDGES) 18 July 1989 (1989-07-18)		
The present search report has been drawn up for all claims			
Place of search BERLIN		Date of completion of the search 7 February 2000	Examiner Krieger, P
CATEGORY OF CITED DOCUMENTS X : particularly relevant if taken alone Y : particularly relevant if combined with another document of the same category A : technological background O : non-written disclosure P : intermediate document T : theory or principle underlying the invention E : earlier patent document, but published on, or after the filing date D : document cited in the application L : document cited for other reasons & : member of the same patent family, corresponding document			

EPO FORM 1503 03.92 (P4C01)

**ANNEX TO THE EUROPEAN SEARCH REPORT
ON EUROPEAN PATENT APPLICATION NO.**

EP 97 30 1578

This annex lists the patent family members relating to the patent documents cited in the above-mentioned European search report. The members are as contained in the European Patent Office EDP file on
The European Patent Office is in no way liable for these particulars which are merely given for the purpose of information.

07-02-2000

Patent document cited in search report		Publication date	Patent family member(s)	Publication date
EP 353995	A	07-02-1990	JP 1947934 C	10-07-1995
			JP 2040504 A	09-02-1990
			JP 6071863 B	14-09-1994
			JP 1947935 C	10-07-1995
			JP 2041979 A	13-02-1990
			JP 6071864 B	14-09-1994
			CA 1326279 A	18-01-1994
			DE 68912846 D	17-03-1994
			DE 68912846 T	28-07-1994
			US 5001637 A	19-03-1991
JP 04306177	A	28-10-1992	NONE	
JP 02144262	A	04-06-1990	JP 2748456 B	06-05-1998
US 5422810	A	06-06-1995	NONE	
EP 590576	A	06-04-1994	JP 2753782 B	20-05-1998
			JP 6111185 A	22-04-1994
			DE 69301219 D	15-02-1996
			DE 69301219 T	15-05-1996
DE 4115716	A	23-01-1992	JP 2552380 B	13-11-1996
			JP 4019509 A	23-01-1992
			US 5526270 A	11-06-1996
US 4848791	A	18-07-1989	CA 1301278 A	19-05-1992
			DE 68909251 D	28-10-1993
			DE 68909251 T	13-01-1994
			EP 0323899 A	12-07-1989
			JP 1215677 A	29-08-1989
			JP 2836832 B	14-12-1998

EPO FORM P0459

For more details about this annex : see Official Journal of the European Patent Office, No. 12/82

THIS PAGE BLANK (USPTO)